# Errata to "Multivalued Robust Tracking Control of Lagrange Systems: Continuous and Discrete-Time Algorithms" [Sep 17 4436-4450]

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# Comments on "Multivalued robust tracking control of Lagrange systems: Continuous and discrete-time algorithms"

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***Abstract*—Unfortunate mistakes in the statements of Theorems 1 and 6 in the above paper are corrected.**

The first point of [1, Theorem 1] should read

> 1) $\sigma$ is continuous and $\dot{\sigma}$ is essentially bounded on bounded sets.

The sentence before (62) in [1, Theorem 6] should be replaced by

> Then, we can find a subsequence of sampling times $h$ converging to zero such that $(\sigma_h, \tilde{q}_h)$ converges to $(\sigma, \tilde{q})$, where $(\sigma, \tilde{q})$ is a solution of

## References

[1] F. Miranda, B. Brogliato, and F. Castaños, "Multivalued robust tracking control of Lagrange systems: Continuous and discrete-time algorithms," *IEEE Trans. Autom. Control*, vol. 62, pp. 4436 – 4450, Sep. 2017.

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